

ABSTRACT OF THE DISCLOSURE

In a servo controller according to the invention, a position feedback correction unit (3) calculates a first-axis position feedback signal (pmfb1) based on a first-axis position (pm1) as a self-axis position, and a second-axis position (pm2) as an other-axis position; and a deviation between a model position (pa1) and the first-axis position feedback signal (pmfb1) is inputted from a subtracter (5) to a position control unit (4), which performs positional control to output a velocity command. A velocity feedback correction unit (6) calculates a first-axis velocity feedback signal (wmfb1) from a first-axis velocity (wm1) as the self-axis velocity, and a second-axis velocity (wm2) as the other-axis velocity; and the velocity control unit (8) adds a model velocity (wa1) and the velocity command outputted from the position control unit (5), and subtracts the first-axis velocity feedback signal (wmfb1) therefrom, and outputs a feedback torque command (Tfb1) based on the corrected velocity command.